

## IN THE SPECIFICATION

At page 5, beginning with line 23 rewrite the description of Figures 5 and 6 and add the brief description for Figure 7 as follows:

Figure 5 is an enlarged side view of the container handling system of Figure 1 showing the automated loader arm in two positions; ~~and~~

Figure 6 is a greatly enlarged view of a portion of the mechanism of Figure 5; and -

Figure 7 is a schematic diagram of the control system for the container handling system of the invention.

At page 6, beginning with line 19 through page 7, line 5; rewrite the following paragraph.

Figures 1 and 2 depict a side loading refuse truck generally at 20 which represents one of the several types of such vehicles which make use of container handlers such as that shown in the retracted position 22 in Figure 1 and 24 in Figure 2. Truck 20 is shown with ~~as being~~ pivotally attached ~~with the~~ truck body 26 in the lowered refuse collecting or hauling orientation. The illustrated truck body 26 is of a "dropped bottom" variety to accommodate manual side loading and includes a side loading refuse receiving or charging hopper 28 having a lower bottom and side opening to also accommodate manual container dumping attached by an intermediate ramp section 30 which connects to a refuse holding or storage compartment or section 32. Refuse is loaded into ~~to in~~ a side opening in the receiving hopper just above the wall 34 and is thereafter pushed ~~push~~ rearward as by a conventional hydraulic cylinder-operated compactor packing ram (not shown) from the hopper bin 28 into the holding or storage body 32 where it is packed against a heavy tailgate 36 as is well known.

At page 10, line 2 add a new paragraph as follows:

Figure 7 depicts a schematic diagram of a control system for use with the container handling system of the invention. This system includes a central processing microprocessor controller 100 which is programmed to control the operation of this system. The control system

further includes an arm position monitoring sensor 102 which is preferably an angular displacement transducer device associated with the rotation of the output shaft of a rotary actuator or other arm mounting shaft. A linear transducer as at 104 is used to obtain and transmit data regarding the relative extension of the boom so that this information in addition to that related to arm position are constantly supplied to the microprocessor 100. In addition, a boom position control is shown at 106 and an arm speed control at 108 which may control the pivot speed of the arm in relation to the sensed arm position. A grabber control 110 is used to operate the container grabbing and releasing operation in conjunction with the operation of the boom position control 106 and the arm position sensor 102. The operation of this system will next be explained.